1. (Currently Amended) An electronically commutated motor comprising:

a stator, a rotor, and a program-controlled microprocessor, serving to control commutation of the motor; said rotor rotating, during motor operation, through a plurality of commutation angular ranges, during each of which a commutation takes place as the rotor rotates therethrough, each commutation being preceded by:

a) rotation of the rotor through a measuring angular range having a predefined angular relationship with a subsequent associated commutation angular range during which said commutation is to occur, during which measuring angular range data, relating to a time duration variable (t_H) needed by the rotor to rotate through said range, are ascertained;

b) rotation of the rotor through a calculation range, during which a first time interval (t_TI) is calculated, based upon said time duration variable (t_H);

c) a time measuring step, during which a time corresponding to said first time interval (t_TI) is measured, beginning at a predefined angular orientation of the rotor associated with said associated commutation angular range; and

d) an interrupt routine, triggered upon conclusion of said time measuring step, said interrupt routine being operative to control, during said associated commutation angular range, time-advanced commutation, when said motor is operating in a steady state.

~~an apparatus for ascertaining a time variable (t_H) corresponding to a rotation speed dependent time interval required by the rotor to rotate through a predefined angular distance, and being substantially inversely proportional to the rotation speed of the rotor;~~

~~an apparatus which triggers a rotor position dependent interrupt routine at predefined rotor positions;~~

~~an apparatus for calculating a first time interval (t_TI) dependent on that time variable (t_H);~~

~~an apparatus for triggering a motor control interrupt routine at an instant offset (t_TI) from a predefined rotor position, that offset corresponding to the first time interval (t_TI) dependent on the ascertained time variable (t_H);~~

~~wherein the motor control interrupt routine contains program steps for effecting a commutation of the motor.~~

2. (Currently Amended) The motor according to claim 1, wherein the motor control interrupt routine comprises program steps which prevent a commutation from being effected if the first time interval dependent on the ~~sensed~~ ascertained time variable is greater than a time span presently required by the rotor to travel through a predefined angular distance.

3.(Previously Presented) The motor according to claim 2, further comprising:

an apparatus which triggers a rotor position-dependent interrupt routine at predefined rotor positions.

4. (Currently Amended) The motor according to claim 3, wherein:

a timer, controllable by the rotor position-dependent interrupt routines, is provided, in order to ~~sense the~~ ascertain said time variable (t_H). ~~that is substantially inversely proportional to the rotation speed of the rotor.~~

5. (Currently Amended) The motor according to claim 4, wherein:

the timer is also configured to trigger ~~a~~ said motor control interrupt routine.

6. (Currently Amended) The motor according to claim 5, wherein:

the timer is loadable, during a rotor position-dependent interrupt, with a first predefined count value which corresponds to the first time ~~offset~~ interval (t_TI) dependent on the ascertained time variable;

and which brings about a motor control interrupt after counting that first predefined count value.

7. (Previously Presented) The motor according to claim 3, wherein:

a rotor-position-dependent interrupt has a higher priority than a motor control interrupt.

8. (Previously Presented) The motor according to claim 4, wherein:

the timer, which in operation presents a timer value, is loadable, during a motor control interrupt, with a predefined count value;

and, subsequent to that loading operation, a count is performed until the next rotor position-dependent interrupt, so as to ascertain, by taking the difference between the predefined count value and the timer value upon reaching the next rotor position-dependent interrupt, a time offset between these interrupt operations.

9. (Previously Presented) The motor according to claim 8, further comprising:

an autoreload register for loading the predefined count value, which register stores the first predefined count value and feeds it to the timer during the motor control interrupt as the predefined count value.

10-29 (Cancelled).

30. (Currently Amended) A method of commutating an electronically commutated motor comprising a stator, a rotor and a program-controlled microprocessor serving to control commutation of said motor, comprising the steps of:

a) ascertaining a rotation-speed-dependent value for a time variable (t_H) corresponding to a time interval required by the rotor to rotate through a predefined angular distance, ~~and~~ said time variable being substantially inversely proportional to the rotation speed of the rotor;

b) from that time variable (t_H), calculating, according to a predefined calculation rule, a numerical value (t_TI);

c) measuring, beginning at a predefined first rotor position, a first time interval corresponding to that calculated numerical value;

d) determining when said first time interval has elapsed, and thereafter triggering a commutation (TN);

e) subsequent to the end of said first time interval, measuring a second time interval (t_1) until said rotor reaches a predefined second rotor position;

f) adding the first and second time intervals to obtain, from their sum, a new rotation-speed-dependent value for the time variable (t_H) that is substantially inversely proportional to the rotation speed of the motor.

31. (Previously Presented) The method of claim 30, further comprising the step of:

correcting said sum by at least one correction factor.

32. (Currently Amended) The method according to claim 30, wherein:

said predefined calculation rule comprises

subtracting a predefined time from said time variable, ~~that~~ which time variable is substantially inversely proportional to the rotation speed of the rotor.

33. (Previously Presented) The method according to claim 30, further comprising:

determining whether the first time interval corresponding to the calculated numerical value is greater than a time offset between the predefined first rotor position and the predefined second rotor position, and, if so, directly sensing the time offset between those two rotor positions and using the time offset as said time variable that is substantially inversely proportional to the rotation speed of the motor.

34. (Previously Presented) The method according to claim 30, further comprising:

comparing said time variable that is substantially inversely proportional to the rotation speed of the motor to a predefined value corresponding to a minimum rotation speed;

storing a logical value, corresponding to a result of said comparison result; and

if that logical value has a predefined value, suppressing the triggering of a commutation that would otherwise be accomplished after the first time has elapsed.

35. (Previously Presented) The method according to claim 30, further comprising:

detecting when a predefined rotor position is reached, and

executing a rotor position-dependent interrupt with an interrupt routine at the beginning of which a timer, providing time measurement, is stopped, and its instantaneous value is stored in a variable.

36. (Previously Presented) The method according to claim 35, further comprising:

in the rotor-position-dependent interrupt routine, stopping the timer providing time measurement, then loading the timer with a numerical value previously calculated in accordance with the predefined calculation rule, and thereafter restarting the timer.

37. (Previously Presented) The method according to claim 36, further comprising:

using the time span, between the stopping of the timer providing time measurement and the restarting thereof, as a correction factor during said step of ascertaining the time variable that is substantially inversely proportional to the rotation speed of the motor.

38. (Currently Amended) The method according to claim 30, further comprising the steps of:

ascertaining, beginning at a predefined rotor position, said rotation-speed-dependent value for said time variable which corresponds to a time interval required by the rotor to travel through a predefined angular distance, ~~from a first angular rotor position, and~~ said time interval being substantially inversely proportional to the rotation speed of the rotor;

using said ascertained time variable in calculating said first time interval corresponding to the calculated numerical value, which is measured from ~~a~~ said predefined first rotor position; and

measuring said first time interval, corresponding to said calculated numerical value, beginning at said ~~first angular~~ predefined rotor position that is reached again after ~~one~~ a subsequent full rotor revolution.

39. (Previously Presented) The method according to claim 30, further comprising:

determining whether sufficient processor time is available for executing a predetermined non-time critical process step and, if so,

executing a subroutine which performs said predetermined non-time-critical process step.

40. (Previously Presented) The method according to claim 39, further comprising:

calculating said rotation-speed-dependent value for said time variable that is substantially inversely proportional to the rotation speed of the motor, and calculating the numerical value on which measurement of the first time interval is based, as part of said subroutine executed when processor time is available.

41. (Previously Presented) The method according to claim 30, further comprising:

loading, from a nonvolatile memory associated with the motor, at least one parameter, necessary for calculations, into a random-access memory of the microprocessor.

42. (Previously Presented) The method according to claim 41, further comprising:

modifying, via a bus connection, at least one value stored in said nonvolatile memory.

43. (Currently Amended) An electronically commutated motor <u>for operation with advanced commutation</u>, comprising:

a stator,

a rotor,

a microprocessor adapted for executing a program which controls commutation of the motor,

<u>a timer,</u>

<u>means for deriving a start value, for use in said timer, as a function of a rotation-dependent time interval which the rotor has required, in an associated time period preceding a just-completed commutation, to rotate through a predefined rotation angle, said start value being</u> ~~means for starting a timer with a predefined start value~~ dependent on a time variable that is substantially inversely proportional to the rotation speed of the motor at at least one predefined rotational position of said rotor;

means, responsive to said timer, for triggering an interrupt in said program of said microprocessor after elapse of a time interval having a duration dependent on the start value; and

means for commutating said motor during said interrupt.

44. (Cancelled) The motor according to claim 43, further comprising:

means for deriving the start value of the timer as a function of a rotation-speed-dependent time interval which the rotor has required, in a time period preceding that commutation, to rotate through a predefined rotation angle.

45. (Currently Amended) The motor according to claim 43 ~~44~~, wherein said means for deriving further comprises:

means for subtracting a predefined time from the rotation-speed-dependent time interval as part of a calculation of the start value.

46. (Currently Amended) A method of determining a rotation-speed-dependent variable in an electronically commutated motor which includes

a stator,

a permanent-magnet rotor,

a galvanomagnetic sensor controlled by that rotor, a microprocessor, a control program associated with that microprocessor, and a timer, comprising the steps of:

a) converting an output signal of the galvanomagnetic sensor into a substantially square-wave signal;

b) sensing, in the microprocessor, predefined signal changes of the square-wave signal and converting each signal change into a respective rotor-position-dependent interrupt;

c) at a rotor-position-dependent interrupt, recording a first counter status of the timer;

d) at a rotor position-dependent interrupt subsequent thereto, recording a second counter status of the timer;

e) calculating a difference between the two counter statuses and deriving, from said difference, a value which corresponds to a time interval required by the rotor to travel through a predefined rotation angle; and using said value as the rotation-speed-dependent variable.

47. (Currently Amended) An electronically commutated motor (M) comprising:

a stator and a rotor,

a program-controlled microprocessor, adapted for controlling the commutation of the motor; and

a rotor position sensor whose output signal is applied, for purposes of analysis by the microprocessor, to an interrupt-capable input of ~~that~~ said microprocessor~~, said~~ for processing therein;

said microprocessor furnishing, at at least one output of the microprocessor, a control signal, for commutation of the motor, that is shifted, with respect to the signal of the rotor position sensor, by a shift time, the duration of the shift time being a function of the rotation speed of said motor.

48. (Previously Presented) The electronically commutated motor according to claim 47, wherein the microcontroller comprises at least one interrupt-capable timer with which the at least one output of the microprocessor, serving to deliver the control signal, is influenced.

49. (Previously Presented) The electronically commutated motor according to claim 48, wherein:

the timer is, in a specific state, automatically reloaded with a value and restarted.

50. (Previously Presented) The electronically commutated motor according to claim 48, wherein:

the microprocessor triggers an interrupt at each change in the signal of the rotor position sensor; and wherein:

the timer and the interrupts are used to measure a value dependent on rotor speed.

51. (Previously Presented) The electronically commutated motor according to claim 49, wherein:

the microprocessor triggers an interrupt at each change in the signal of the rotor position sensor; and wherein:

the timer and the interrupts are used to measure a value dependent on rotor speed.